

- c) a total plumb error defined by components, P_I and P_{II} , being two separate angular values defining the tilt of the instrument as related to the plumb line through the same; and
- d) using these determined values in continuously controlling the alignment when aiming the instrument.

2. (Original) A method of operating a surveying instrument according to claim 1, wherein the adjustment is performed using a controller comprising a microprocessor for controlling the alignment of the instrument.

3. (Currently Amended) A method of operating a surveying instrument according to claim 2, wherein said controller is adapted to automatically compensate for determined errors while following an arbitrary straight line between two points using the following steps: define two points A and B on a plane; calculate an angle Φ , a height Z_0 , and an angle H_0 , where Φ being the vertical angle between a projection of said arbitrary line in the YZ-plane through the instrument 710 (0,0,0) and the Z-axis, the height Z_0 being the height where said projection crosses the Z-axis, and the angle H_0 , being the angle in the XY-plane between the Y-axis and a line perpendicular to the projection of the line between A and B, and using these values to control the movement of the instrument.

4. (Currently Amended) A method of operating a surveying instrument according to claim 3, wherein when aiming in an arbitrary horizontal angle H the corresponding vertical angle V to a point on the line A - B is calculated from Z_0 , H_0 and Φ , this value V is then used as a reference input to the a vertical servomotor, resulting in that the vertical aiming is so controlled that the instrument will follow a straight line between said two points when manipulating a knob for horizontal aiming.

5. (Currently Amended) A method of operating a surveying instrument according to claim 3, wherein when aiming in an arbitrary vertical angle V the corresponding horizontal angle H to a point on the line A - B, where H is calculated from Z_0 , H_0 and Φ , this value H is ~~the~~ used as ~~an input as~~ a reference input to ~~the~~ a horizontal servomotor, resulting in the instrument ~~to follow~~ following a straight line between said two points when manipulating a knob for vertical aiming.

6. (Currently Amended) A method of operating a surveying instrument according to claim 2, wherein said controller is adapted to automatically compensate for determined errors while following a horizontal straight line on a plane using the following steps: define the plane orientation by measuring the position of at least two points on the plane; input the desired height value h ; calculate the perpendicular angle H_0 to the projection of the desired horizontal line in the XY-plane; for any horizontal angle H , calculate the corresponding vertical angle V , and use this value to control ~~the~~ a vertical servo.

7. (Currently Amended) A method of operating a surveying instrument according to claim 2 wherein the aiming of the movable unit (20) may be effected using a vertical servomotor and a horizontal servomotor and where the horizontal servomotor is controlled to compensate for said errors, resulting in that when a knob for vertical aiming is manipulated, the aiming will follow a plump line.

8. (Currently Amended) A method of operating a surveying instrument (10), said instrument having a movable unit (20) that is controllably rotatable around a first axis (50) and around a second axis (90), wherein said second axis (90) may be inaccurately positioned so that it deviates from a true vertical axis, and said first axis (50) may deviate from being orthogonal to the second axis (90); the method comprising the steps of:
a) setting a horizontal reference value (R_H) indicative of a desired horizontal orientation of said movable unit (20);

- b) detecting a horizontal orientation value (H_s) indicative of a current rotational orientation around said second axis (± 90);
- c) receiving a horizontal orientation correction value ($H_{EC}; DH$) indicative of a horizontal orientation deviation of said movable unit (± 20); wherein said horizontal orientation correction value ($H_{EC}; DH$) is generated in dependence of a transverse plumb error value ($P_l; P'_l$); said transverse plumb error value ($P_l; P'_l$) being dependent on said horizontal orientation of said movable unit (± 20); and

wherein said received horizontal orientation correction value ($H_{EC}; DH$) is dependent on the vertical orientation (V) of the movable unit (± 20) so as to compensate for horizontal orientation deviations that may occur as a consequence of pivoting around said first axis (± 50);

- d) generating a horizontal position value (H) indicative of a current horizontal orientation of said movable unit (± 20) in response to said detected horizontal orientation value (H_s) and said horizontal orientation correction value ($H_{EC}; DH$);
- e) generating a horizontal error value (e_H) in dependence on said horizontal position value (H) and said horizontal reference value (R_H);
- f) automatically controlling the horizontal orientation of the movable unit (± 20) in dependence of said horizontal error value (e_H).

9. (original) The method according to claim 8, further comprising

- g) repeating steps b) to f) of claim 1 until said horizontal error value (e_H) is smaller than a predetermined threshold value (D_F).

10. (Currently Amended) The method according to claim 8 or 9, wherein

said horizontal orientation correction value ($H_{EC}; DH$) is dependent on a predicted transverse plumb error value (P'_l); and wherein

the predicted transverse plumb error value (P'_l) is generated in dependence on said detected horizontal orientation value (H_s).

11. (Currently Amended) The method according to claim 8 ~~or 9~~, wherein
said horizontal orientation correction value (H_{EC} ; DH) is generated in response a
measured transverse plumb error value (P_l); said measured transverse plumb error value
(P_l) being inherently dependent on the horizontal position of the movable unit (20) when
the transverse plumb error (P_l) deviates from zero.

12. (Currently Amended) The method according to ~~any one of claims 8, 9, 10 or 11~~
claim 8 wherein

steps b), d), e) and f) of ~~claim 1~~ are performed with a first repetition frequency;
and wherein

said horizontal orientation correction value (H_{EC} ; DH) is updated with a second
repetition frequency; said second repetition frequency being lower than said first
repetition frequency.

13. (Currently Amended) The method according to claim 12 ~~when dependent on claim~~
~~9, 10 or 11~~, wherein

said transverse plumb error value is updated with said second repetition
frequency.

14. (Currently Amended) The method according to ~~any one of claims 9—13~~ claim 9,
wherein

said predetermined threshold value (D_F) is less than ten arcseconds.

15. (Currently Amended) The method according to ~~any one of claims 8—14~~ claim 8,
wherein

said predetermined threshold value (D_F) is less than one arcsecond.

16. (Currently Amended) The method according to ~~any one of claims 8—15~~ claim 8,
further comprising the step of:

pivoting said movable unit (20) around said first axis (50) so as to change a vertical orientation (V) of said movable unit (20).

17. (Currently Amended) The method according to ~~any one of claims 8—16~~ claim 8, wherein:

said vertical orientation (V) of the movable unit (20) is generated in dependence of a longitudinal plumb error value (P_{II} ; P'_{II}); said longitudinal plumb error value (P_{II} ; P'_{II}) being dependent on said horizontal orientation of said movable unit (20).

18. (Currently Amended) A method of operating a surveying instrument (10) having a movable unit (20) that is controllably rotatable around a first axis (50) and around a second axis (90), wherein said second axis (90) may be inaccurately positioned so that it deviates from a true vertical axis, and said first axis (50) may deviate from being orthogonal to the second axis (90); the method comprising the steps of:

setting a desired first horizontal orientation of said movable unit (20) so that a horizontal component of the aim of a sight line (128) of said surveying instrument (10) is directed in a first compass bearing;

pivoting said movable unit (20) around said first axis (50) so as to change a vertical orientation (V) of said movable unit (20) until said horizontal component of the aim of said sight line (128) of said surveying instrument (10) is directed in a second compass bearing; said second compass bearing deviating from said first compass bearing;

generating a horizontal position value (H) indicative of a current horizontal orientation of said movable unit (20) in response to a horizontal orientation correction value (H_{EC}); said horizontal orientation correction value (H_{EC}) being dependent on the vertical orientation (V) of the movable unit (20) so as to compensate for horizontal orientation deviations that may occur as a consequence of pivoting around said first axis (50);

automatically controlling a horizontal orientation of the movable unit (20) in dependence of said horizontal position value (H) so that said second compass bearing is opposite said first compass bearing.

19. (Currently Amended) A method of operating a surveying instrument (10) having a movable unit (20) that is controllably rotatable around a first axis (50) and around a second axis (90), wherein said second axis (90) may be inaccurately positioned so that it deviates from a true vertical axis, and said first axis (50) may deviate from being orthogonal to the second axis (90); the method comprising the steps of:

- a) setting a vertical reference value (R_V) indicative of a desired vertical orientation of said movable unit (20);
- b) detecting a vertical orientation value (V_s) indicative of a current rotational orientation around said first axis (50);
- c) receiving a vertical orientation correction value (V_{EC} ; DV) indicative of a vertical orientation deviation of said movable unit (20); wherein

said vertical orientation correction value (V_{EC} ; DV) is generated in dependence of a longitudinal plumb error value (P_{II} ; P'_{II}); said longitudinal plumb error value (P_{II} ; P'_{II}) being dependent on a horizontal orientation of said movable unit (20);

- d) generating a vertical position value (V) indicative of a current vertical orientation of said movable unit (20) in response to said detected vertical orientation value (V_s) and said vertical orientation correction value (V_{EC} ; DV);
- e) generating a vertical error value (e_V) in dependence on said vertical position value (V) and said vertical reference value (R_V);
- f) automatically controlling a vertical orientation of the movable unit (20) in dependence of said vertical error value (e_V).

20. (Original) The method according to claim 19, further comprising

- g) repeating steps b) to f) until said vertical error value (e_V) is smaller than a predetermined threshold value (D_{VF}).

21. (Currently Amended) The method according to claim 19 ~~or 20~~, wherein
said vertical orientation correction value (V_{EC}; DV) is dependent on a predicted
longitudinal plumb error value (P'_{II}); and wherein
the predicted longitudinal plumb error value (P'_{II}) is generated in dependence on
a detected horizontal orientation value (H_s).

22. (Currently Amended) The method according to claim 19 ~~or 20~~, wherein
said vertical orientation correction value (V_{EC}; DV) is generated in response a
measured longitudinal plumb error value (P_{II}); said measured longitudinal plumb error
value (P_{II}) being inherently dependent on the current horizontal position of the movable
unit (20).

23. (Currently Amended) The method according to any one of claims 19 to 22 claim
19, wherein

steps b), d), e) and f) of claim 12 are performed with a first repetition frequency;
and wherein

said vertical orientation correction value (V_{EC}; DV) is updated with a second
repetition frequency; said second repetition frequency being lower than said first
repetition frequency.

24. (Currently Amended) The method according to claim 19 ~~when dependent on claim~~
~~20, 21 or 22~~, wherein said plumb error value is updated with said second repetition
frequency.

25. (Currently Amended) The method according to any one of claims 20—24 claim
20, wherein said predetermined threshold value (D_{VF}) is less than ten arcseconds.

26. (Currently Amended) The method according to ~~any one of claims 20—24~~ claim 20, wherein said predetermined threshold value (D_{VF}) is less than one arcsecond.

27. (Currently Amended) The method according to ~~any one of claims 20—26~~ claim 20, further comprising the step of:

pivoting said movable unit (20) around said second axis (90) so as to change a horizontal orientation of said movable unit (20).

28. (Currently Amended) A surveying instrument (10) having a movable unit (20) that is controllably rotatable around a first axis (50) and around a second axis (90), wherein said second axis (90) may be inaccurately positioned so that it deviates from a true vertical axis, and said first axis (50) may deviate from being orthogonal to the second axis (90); the surveying instrument further comprising:

means for generating a transverse plumb error value ($P_l; P'_l$); said transverse plumb error value ($P_l; P'_l$) being dependent on said horizontal orientation of said movable unit (20);

a horizontal error corrector (412) adapted to generate a horizontal orientation correction value ($H_{EC}; DH$) in dependence of a vertical position value (V) and said transverse plumb error value ($P_l; P'_l$); wherein said vertical position value (V) is indicative of a vertical orientation of said movable unit (20); and

a controller (700) having:

- a) an input (390) for receiving a horizontal reference value (R_H) indicative of a desired horizontal orientation of said movable unit (20);
- b) a sensor for detecting a horizontal orientation value (H_s) indicative of a current rotational orientation around said second axis (90);
- c) an input for receiving said horizontal orientation correction value ($H_{EC}; DH$) indicative of a horizontal orientation deviation of said movable unit (20); and

- d) a horizontal position generator (372) adapted to generate a horizontal position value (H) indicative of a current horizontal orientation of said movable unit (20) in response to said detected horizontal orientation value (Hs) and said horizontal orientation correction value (H_{EC}; DH); and
- e) means for generating a horizontal error value (e_H) in dependence on said horizontal position value (H) and said horizontal reference value (R_H);
wherein
- f) said controller is adapted to automatically control the horizontal orientation of the movable unit (20) in dependence of said horizontal error value (e_H).

29. (Currently Amended) The surveying instrument (10) according to claim 28, wherein

 said controller is adapted to control the horizontal orientation of the movable unit (20) so that said horizontal error value (e_H) is smaller than a predetermined threshold value (D_F).

30. (Currently Amended) The surveying instrument (10) according to claim 28 or 29, wherein said controller is adapted to control the orientation of the movable unit (20) such as to compensate for a detected trunnion error.

31. (Currently Amended) The surveying instrument (10) according to ~~any of claims 28 to 30~~ claim 28, wherein

 said movable unit (20) further comprises optical equipment defining a sight line (128) for allowing said movable unit (20) to be aimed at a target position; wherein said sight line (128) may deviate from being orthogonal to the first axis (50); said deviation constituting a Horizontal Collimation error;

 said surveying instrument (10) further comprising a memory (355) for storing an established Horizontal Collimation error value (C_H); and wherein

said horizontal error corrector (412) has an input coupled to receive said established Horizontal Collimation error value (C_H); said horizontal error corrector (412) being adapted to generate said horizontal orientation correction value (H_{EC} ; DH) in dependence of said established Horizontal Collimation error value (C_H) so as to obtain compensation for said Horizontal Collimation error.

32. (Currently Amended) The surveying instrument (10) according to claim 28, 29 or 30, wherein said means for generating a transverse plumb error value (P_I ; P'_I) comprises a predictor adapted to generate a predicted transverse plumb error value (P'_I) in dependence on said detected horizontal orientation value (H_s).

33. (Currently Amended) The surveying instrument (10) according to claim 32, wherein said horizontal error corrector (412) is adapted to generate said horizontal orientation correction value (H_{EC} ; DH) in dependence of said predicted transverse plumb error value (P'_I).

34. (Currently Amended) The surveying instrument (10) according to ~~any one of claims 28 to 33~~ claim 28 wherein

said controller (700) is adapted to generate an updated horizontal error value (e_H) with a first repetition frequency; and wherein

said horizontal error corrector (412) is adapted to generate an updated horizontal orientation correction value (H_{EC} ; DH) with a second repetition frequency; said second repetition frequency being lower than said first repetition frequency.

35. (Currently Amended) The surveying instrument (10) according to claim 26 ~~when dependent on claim 28, 29, 30, 31, 32 or 33~~, wherein

said transverse plumb error value is updated with said second repetition frequency.

36. (Currently Amended) The surveying instrument (10) according to ~~any one of claims 28–35~~ claim 28, further comprising:

means for generating a longitudinal plumb error value (P_{II} ; P'_{II}); said longitudinal plumb error value (P_{II} ; P'_{II}) being dependent on said horizontal orientation of said movable unit (20);

a vertical error corrector (292) adapted to generate a vertical error correction value (V_{EC}) in dependence of said longitudinal plumb error value (P_{II} ; P'_{II});

a sensor for detecting a vertical orientation value (V_s) indicative of a current rotational orientation around said first axis (50); and

a vertical position generator (272) adapted to generate said vertical position value (V) of the movable unit (20) in dependence of said vertical error correction value (V_{EC}) and said detected vertical orientation value (V_s); and wherein

said horizontal error corrector (412) is adapted to generate said horizontal orientation correction value (H_{EC} ; DH) in dependence of said generated vertical position value (V) and said transverse plumb error value (P_I ; P'_I).

37. (Currently Amended) A surveying instrument (10) having a movable unit (20) that is controllably rotatable around a first axis (50) and around a second axis (90), wherein said second axis (90) may be inaccurately positioned so that it deviates from a true vertical axis, and said first axis (50) may deviate from being orthogonal to the second axis (90); the surveying instrument (10) comprising:

means for generating a longitudinal plumb error value (P_{II} ; P'_{II}); said longitudinal plumb error value (P_{II} ; P'_{II}) being dependent on said horizontal orientation of said movable unit (20);

a vertical error corrector (292) adapted to generate a vertical error correction value (V_{EC}) in dependence of said longitudinal plumb error value (P_{II} ; P'_{II});

a controller (700) having:

- a) an input (290) for a vertical reference value (R_V) indicative of a desired vertical orientation of said movable unit (20);

- b) a sensor for detecting a vertical orientation value (Vs) indicative of a current rotational orientation around said first axis (50); and
- c) an input (273) for receiving a vertical orientation correction value (V_{EC}; DV) indicative of a vertical orientation deviation of said movable unit (20);
 - wherein

 said vertical orientation correction value (V_{EC}; DV) is generated in dependence of a longitudinal plumb error value (P_{II}; P'_{II}); said longitudinal plumb error value (P_{II}; P'_{II}) being dependent on said horizontal orientation of said movable unit (20);
- d) a vertical position generator (272) adapted to generate a vertical position value (V) of the movable unit (20) in dependence of said vertical error correction value (V_{EC}) and said detected vertical orientation value (Vs);
- e) means for generating a vertical error value (e_V) in dependence on said vertical position value (V) and said vertical reference value (R_V); wherein
- f) said controller is adapted to automatically control a vertical orientation of the movable unit (20) in dependence of said vertical error value (e_V).

38. (Currently Amended) The surveying instrument (10) according to claim 37, wherein

 said controller is adapted to control the vertical orientation of the movable unit (20) so that said vertical error value (e_V) is smaller than a predetermined threshold value (D_{VF}).

39. (Currently Amended) The surveying instrument (10) according to claim 37 or 38, wherein

 said means for generating a longitudinal plumb error value (P_{II}; P'_{II}) comprises a predictor (226) adapted to generate a predicted longitudinal plumb error value (P'_{II}) in dependence on said detected horizontal orientation value (H_S).

40. (Currently Amended) An error compensation system for a surveying instrument comprising:

an automatic error measurement system for detecting a tilt error and an error due to mechanical imperfections in said surveying instrument; and

a controller adapted to automatically compensate for said detected errors by controlling a servo system of the instrument so as to correct for detected errors when operating said surveying instrument.

41. (Original) The error compensation system according to claim 40, wherein said detected errors include a trunnion error (T).

42. (Currently Amended) The error compensation system according to claim 40, ~~41~~, wherein said detected errors include a horizontal collimation error (C_H).

43. (Currently Amended) The error compensation system according to claim 40, ~~41~~ or 42, wherein said controller co-operates with said automatic error measurement system so as to cause a sight line of said surveying instrument to move in a vertical direction in response to manual control of a vertical direction reference value (R_V) wherein the error from true verticality is less than a predetermined amount.

44. (Currently Amended) The error compensation system according to claim 40, ~~41~~, or 42, wherein said controller co-operates with said automatic error measurement system to cause a point, on a sight line, at an arbitrary fixed distance from said surveying instrument to move in a horizontal direction in response to manual control of a horizontal direction reference value (R_H) wherein the error from true horizontal is less than a predetermined amount.

45. (Currently Amended) The error compensation system according to ~~any of claims 40 to 44~~ claim 40, wherein

said automatic error measurement system comprises a first error correction generator for generating a vertical error correction value (V_{EC}) and a second error correction generator for generating a horizontal error correction value (H_{EC}) dependent on said detected errors; and wherein

said controller is adapted to achieve said error compensation in dependence of said vertical and horizontal error correction values (V_{EC} , H_{EC}).

46. (Original) The error compensation system according to claim 45, wherein

said first error correction generator is adapted to generate the vertical error correction value (V_{EC}) in dependence on a longitudinal plumb error value (P_{II} ; P'_{II}); and

said second error correction generator is adapted to generate the horizontal error correction value (H_{EC}) in accordance with the following equation:

$$H_{EC} = H_P + C_H / \sin V + (T + P'_I) * \cot V$$

wherein H_P is a constant; T is a detected trunnion axis error; P'_I is a horizontal plumb error value; V is a vertical position value dependent on said vertical error correction value (V_{EC}), and C_H is a horizontal collimation error.

47. (Currently Amended) The error compensation system according to claim 45 or 46 when dependent on claim 38, wherein

said controller is adapted to generate an updated control signal with a first repetition frequency; and wherein

said automatic error measurement system is adapted to generate said error correction values with a second repetition frequency; said second repetition frequency being lower than said first repetition frequency.

48. (Currently Amended) The error compensation system according to any of claims

43 or 44 claim 43, wherein

said predetermined amount is less than ten arcseconds.

49. (Currently Amended) The error compensation system according to ~~any of claims 43 or 44~~ claim 43, wherein

said predetermined amount is less than one arcsecond .

50. (Currently Amended) The error compensation system according to ~~any of claims 43 or 44~~ claim 43, wherein said predetermined amount is less than one third of an arcsecond.

51. (Currently Amended) The error compensation system according to ~~any of claims 48 to 50~~ claim 48, wherein

said controller is adapted to automatically compensate for said detected errors during manual control of said surveying instrument.

52. (Original) The error compensation system according to claim 51, wherein said manual control of said surveying instrument includes manual control of a direction reference value.

53. (Currently Amended) The error compensation system according to ~~any of claims 40 to 50~~ claim 40, wherein said controller is adapted to automatically compensate for said detected errors during remote control of said surveying instrument.

54. (Currently Amended) The error compensation system according to ~~any of claims 40 to 50~~ claim 40, wherein said controller is adapted to automatically compensate for said detected errors during automatic control of said surveying instrument.

55. (Currently Amended) The error compensation system according to ~~any of claims 40 to 54~~ claim 40, wherein said controller is adapted to automatically compensate for determined errors while following an arbitrary straight line between two points using the following steps:

define two points A and B on a plane; calculate an angle Φ , a height Z_0 , and an angle H_0 , where Φ being the vertical angle between a projection of said arbitrary line in the YZ-plane through the instrument 710 (0,0,0) and the Z-axis, the height Z_0 being the height where said projection crosses the Z-axis, and the angle H_0 , being the angle in the XY-plane between the Y-axis and a line perpendicular to the projection of the line between A and B, and using these values to control the movement of the instrument.

56. (Original) The error compensation system according to claim 55, wherein when aiming in an arbitrary horizontal direction H the corresponding vertical angle V to a point on the line A - B is calculated from Z_0 , H_0 and Φ , this value V is the used as an input as reference input to the vertical servomotor, allowing a manipulation of a knob for horizontal aiming such that the vertical aiming is controlled such as allowing the instrument to follow a straight line between said two points.

57. (Original) The error compensation system according to claim 55, wherein when aiming in an arbitrary vertical direction V the corresponding horizontal angle H to a point on the line A - B, where H is calculated from Z_0 , H_0 and Φ , this value H is then used as a reference input to the horizontal servomotor, allowing a manipulation of a knob for vertical aiming such that the horizontal aiming is controlled such as to allow the instrument to follow a straight line between said two points.

58. (Currently Amended) A surveying instrument including an error compensation system according to ~~any of claims 40 to 54~~ claim 40.